3   The objects and features of the present invention, which are believed to be

4   novel, are set forth with particularity in the appended claims. The present invention, both as

5   to its organization and manner of operation, together with further objects and advantages,

6   may best be understood by reference to the following description, taken in connection with

7   the accompanying drawings, of which:

8   Figure 1 is a drawing of a conventional triangulation-based EL System;

9   Figure 2 is an example of what a present day mapping display looks like when

10 using the setup of the system of Figure 1;

11   Figure 3 is a drawing of a preferred embodiment of the present invention and how

12 it is used;

13   Figure 4 is an example of how the probability field mapping display of the present

14 invention can be presented to an EL System operator; and

15   Figure 5 depicts the method for using the mobile DF set and probability fields to

16 determine progressive estimated positions (EPs)."

17

18

1   Please amend the specification at page 11, line 4:

2   "   This invention employs a specialized recursive method in the computer to

3   process the LOB data that is continually being stored. This specialized method is the

4   topic of another patent application entitled: "Technique and Algorithm for Reducing

5   Measurement Uncertainties in Emitter Location Systems," Provisional Application Ser.

6   No. 60/449,442, now "Real-time Emitter Locating System and Method," U.S. Patent

7   Application number 10/785,353, incorporated herein by reference. The whole process

8   begins after a "cross-over" point is first found. A cross-over point is the intersection

9   between the last best LOB data entries from a pair of DF sets. This cross-over point,

10   when fixed on a map, is the original triangulated position (hereafter referred to as the

11   "cross-over position point") of the transmitter. In order to ascertain the changing position

12   of a moving transmitter, the approach depicted in Figure 5 is employed. Once the cross-

13   over position point is found, successive estimated position points (of the transmitter) are

14   determined by moving the mobile DF set in direction 26, generating a connecting vector

15   between the real-time LOB from the mobile DF set to the transmitter, and thereby

16   assigning the EP as being along the connecting vector. These position points (EPs) are

17   then continually fed into a separate system/process that draws the "probability fields"."